

Figure 1.

PRIOR ART

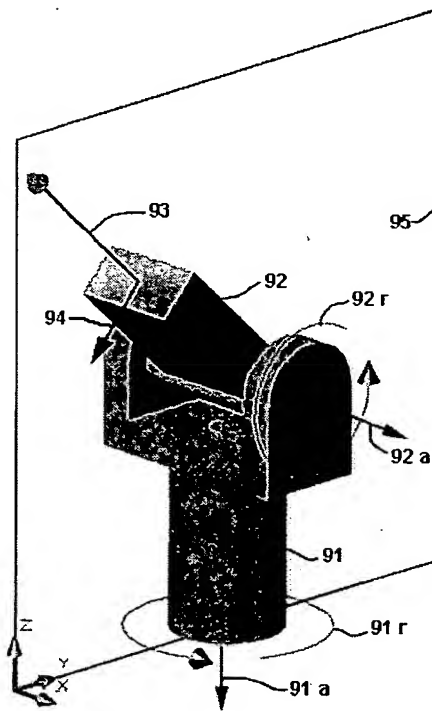


Figure 2

PRIOR ART

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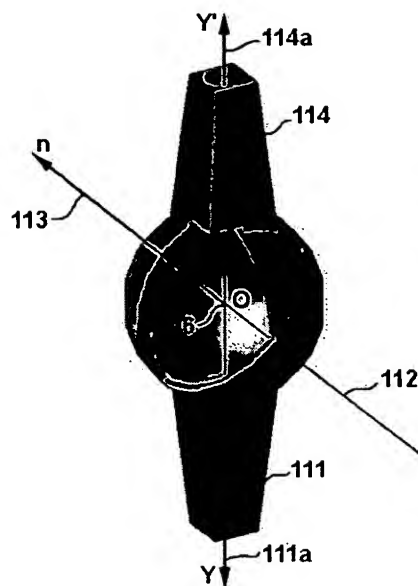


Figure 3a

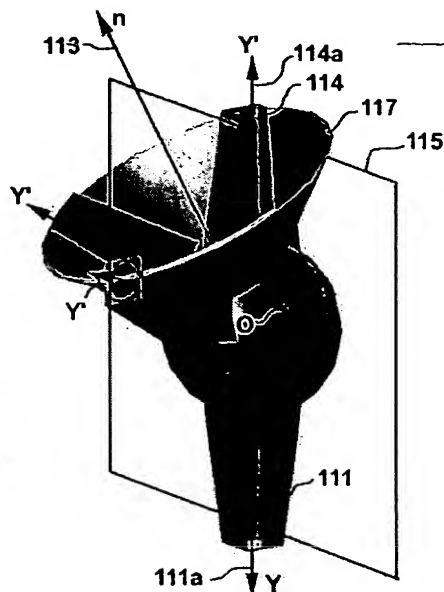


Figure 3b

PRIOR ART

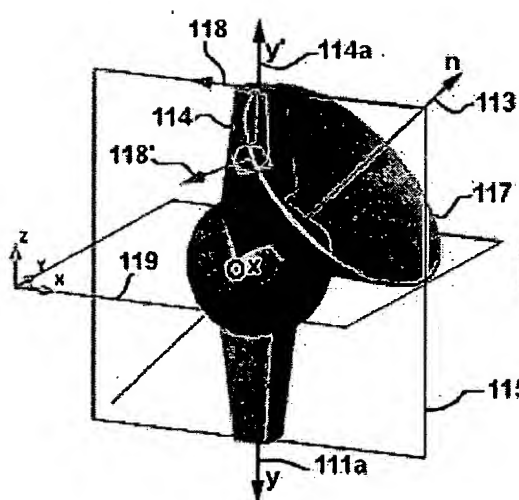


Figure 4a

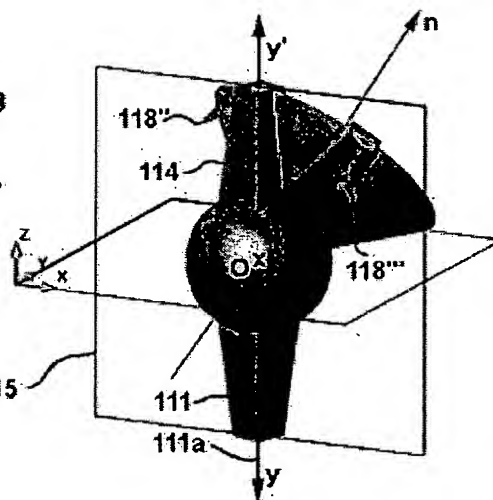


Figure 4b

PRIOR ART

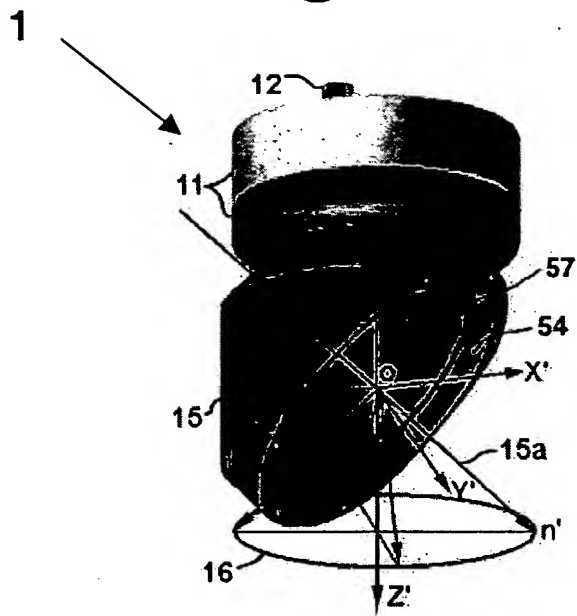


Figure 5a

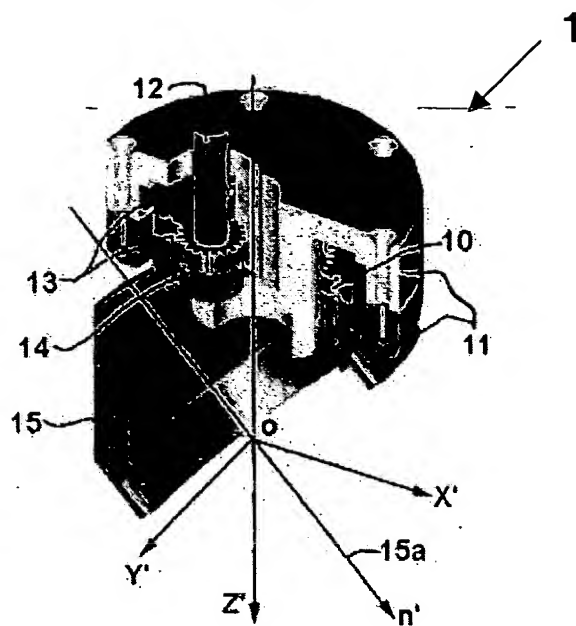


Figure 5b

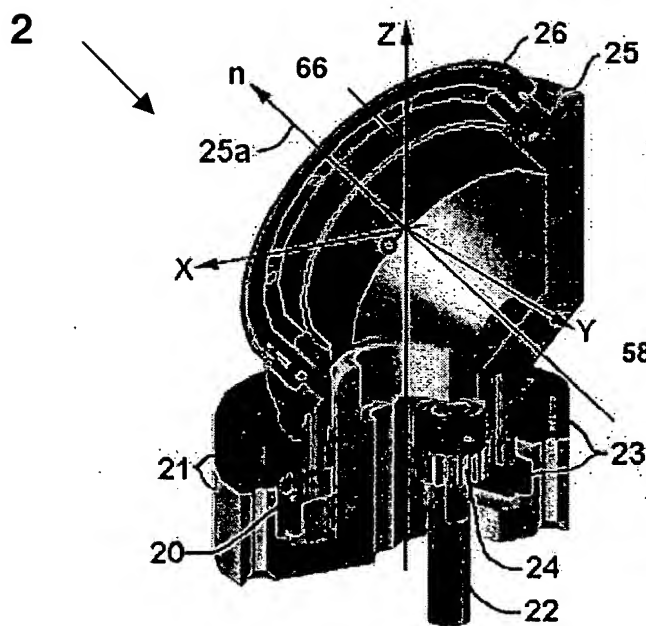


Figure 6a

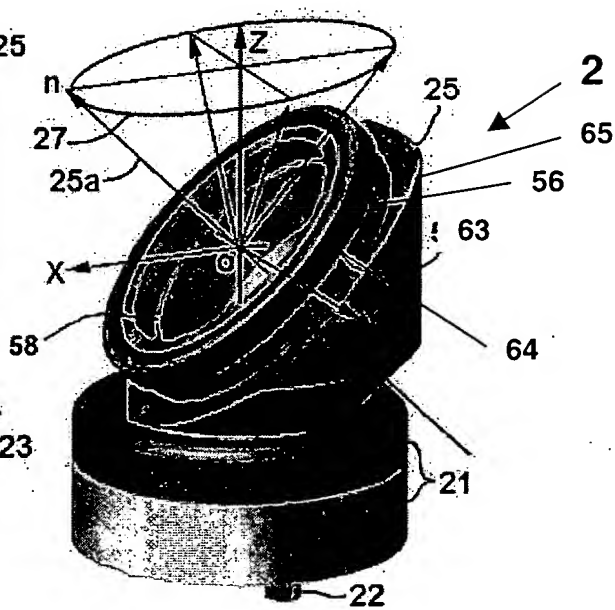


Figure 6b

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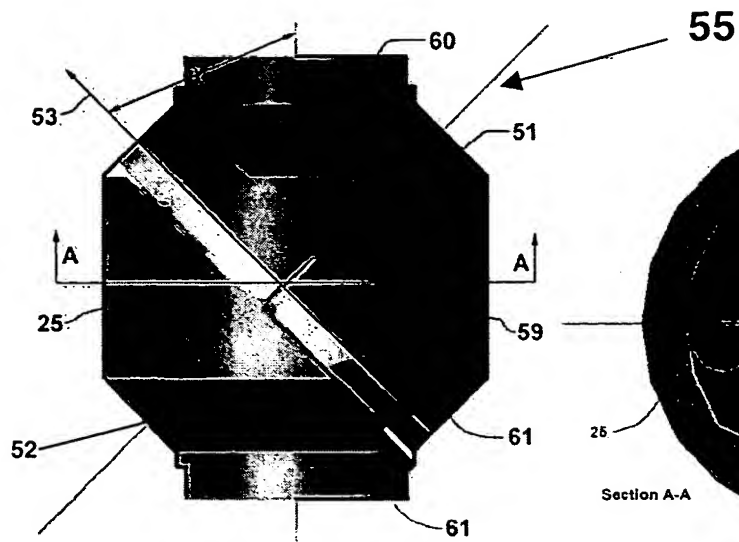


Figure 7a

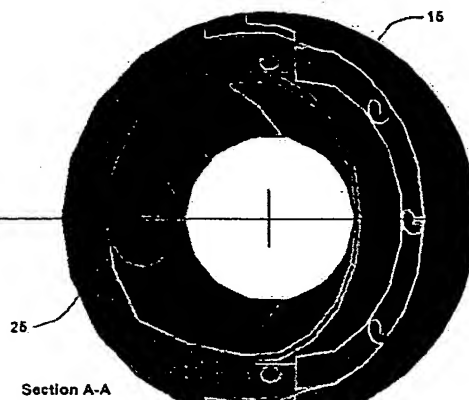


Figure 7b

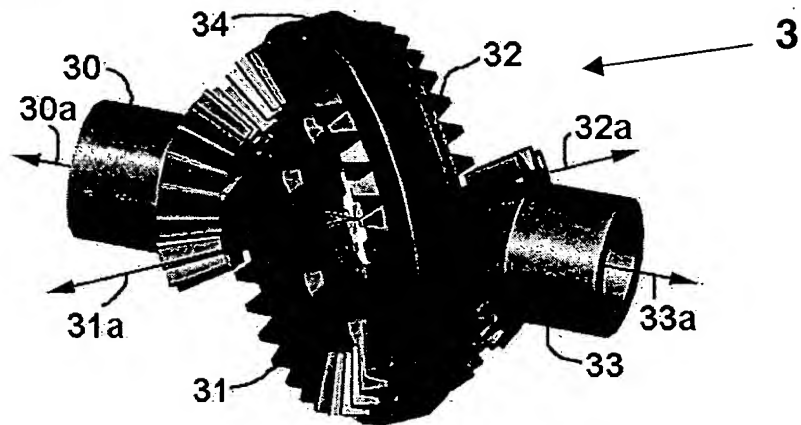


Figure 8

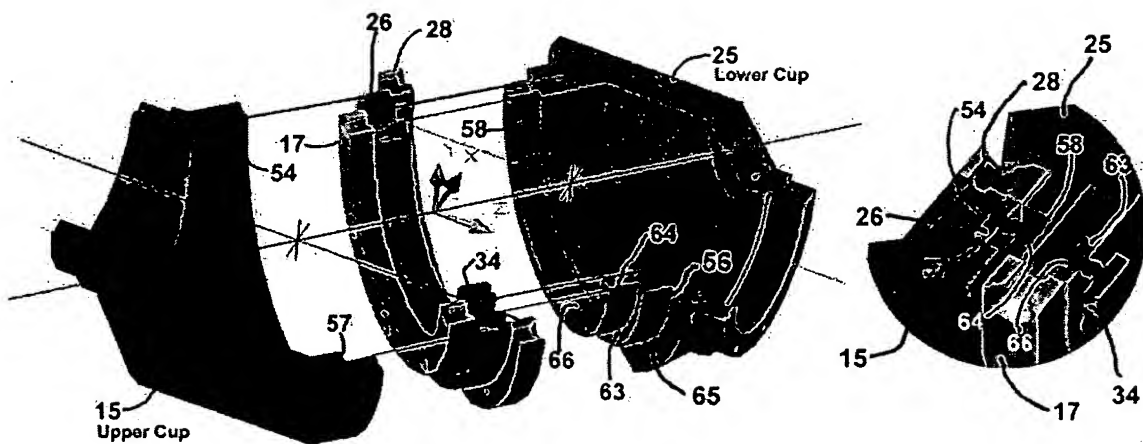


Figure 9a

Figure 9b

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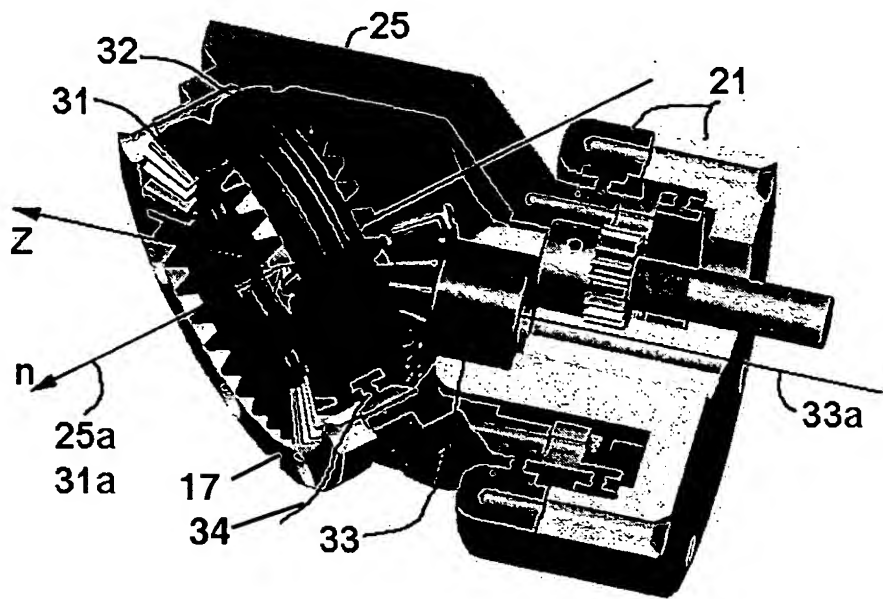


Figure 10

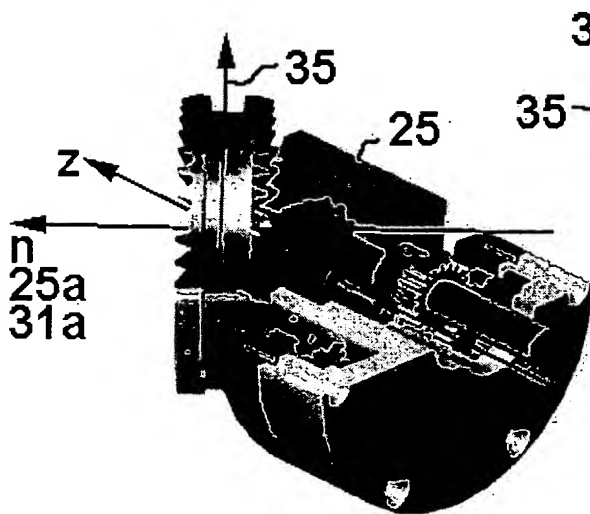


Figure 11a

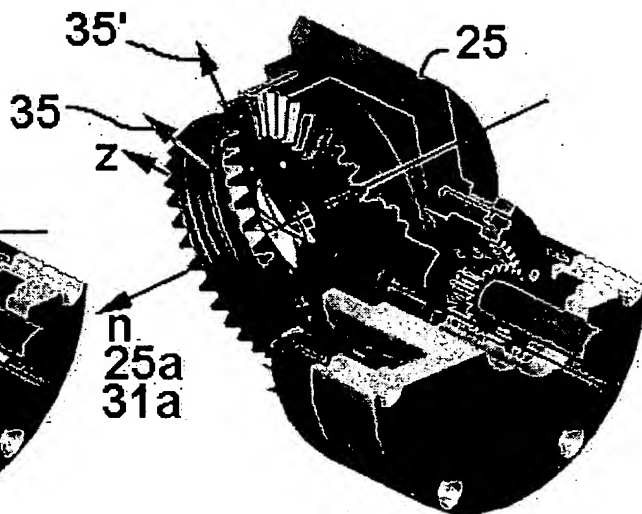


Figure 11b

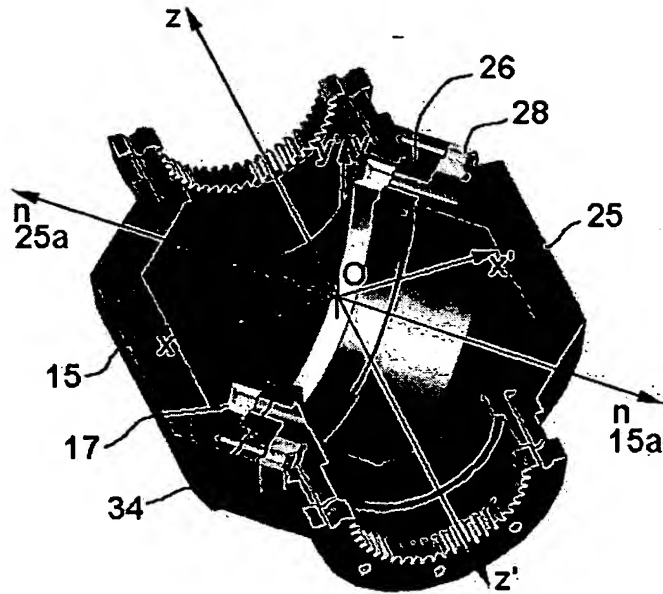


Figure 12

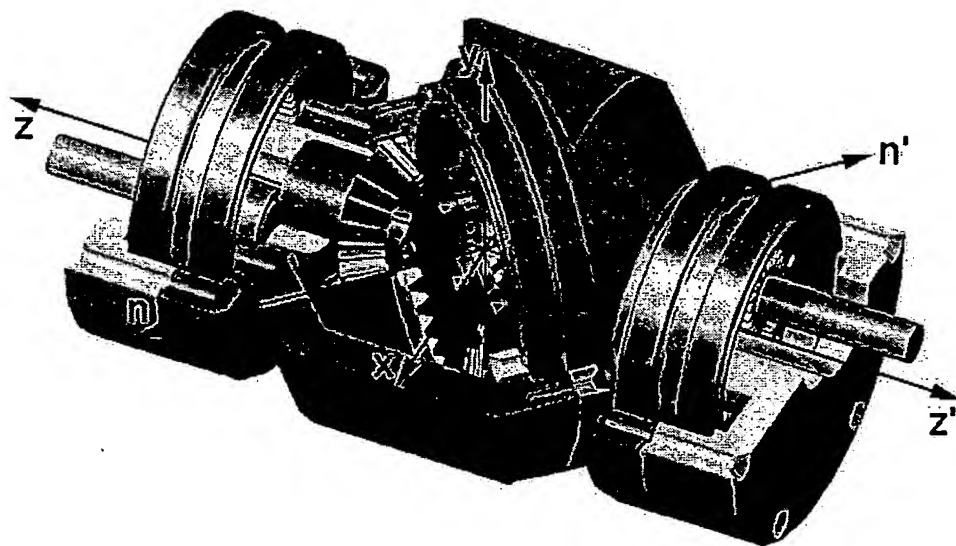


Figure 13

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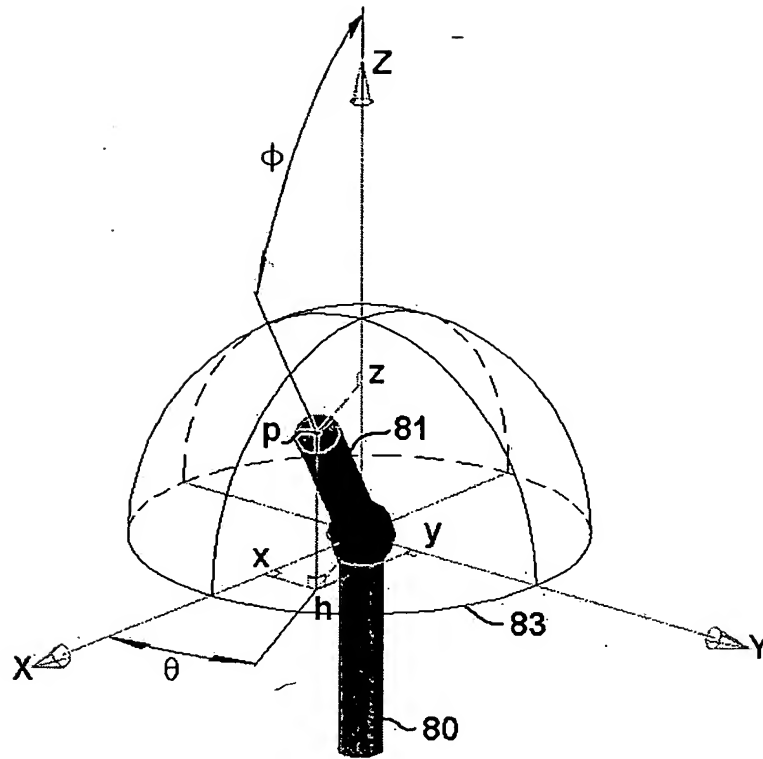


Figure 14

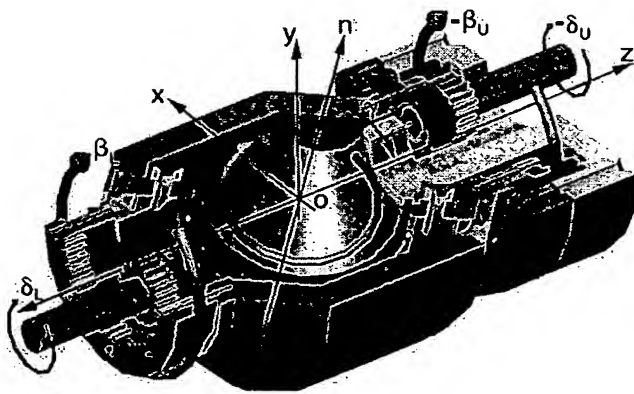


Figure 15a

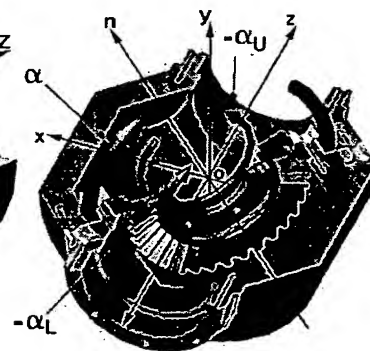


Figure 15b

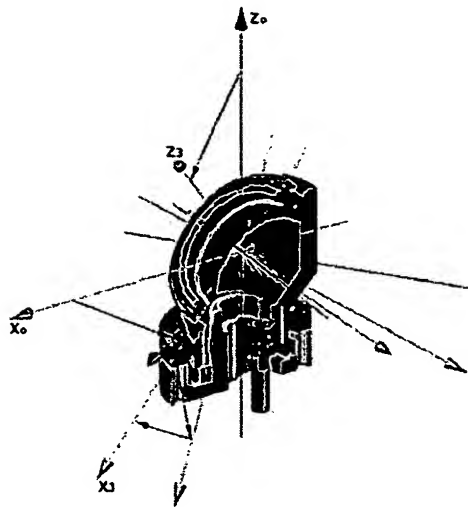


Figure 16a

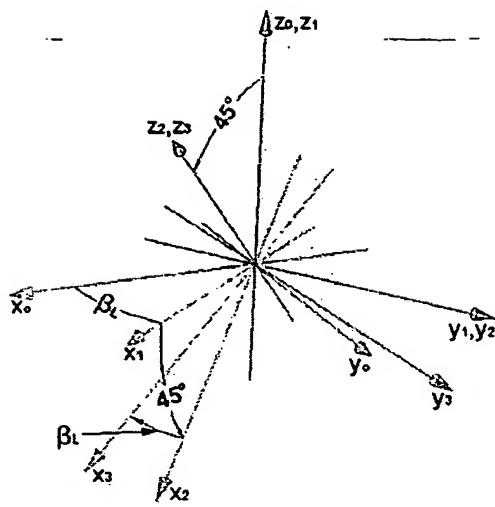


Figure 16b

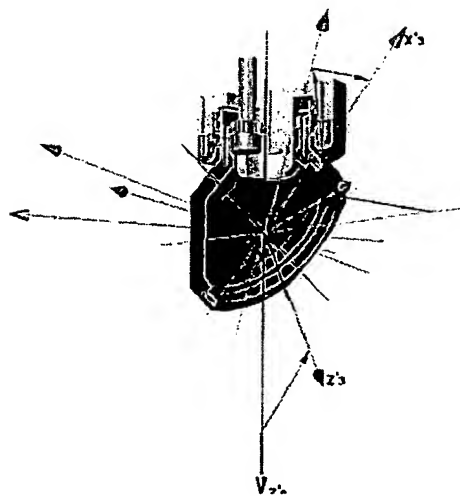


Figure 17a

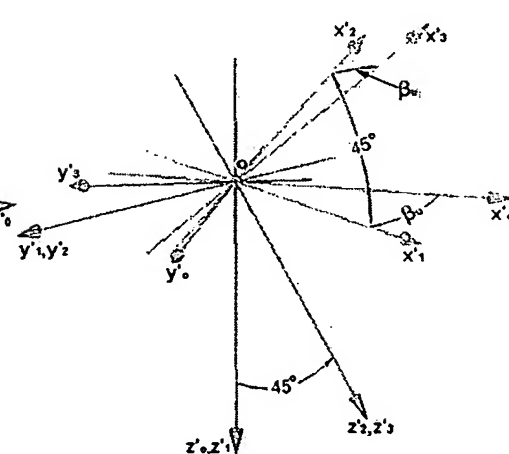


Figure 17b

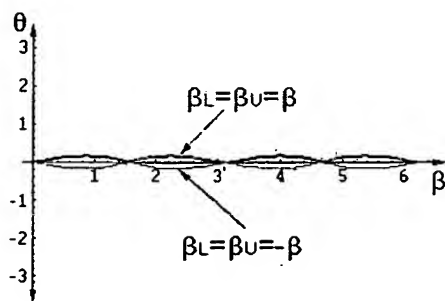


Figure 18a

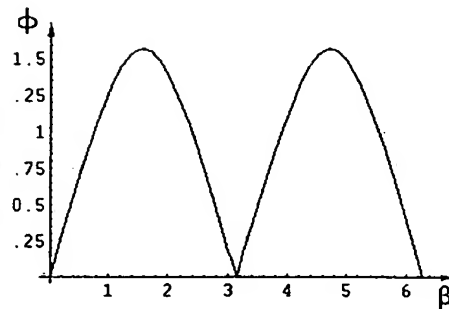


Figure 18b



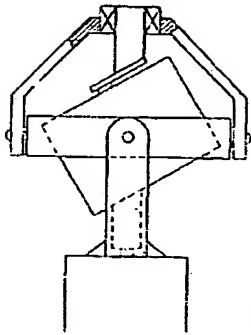


Figure 19a

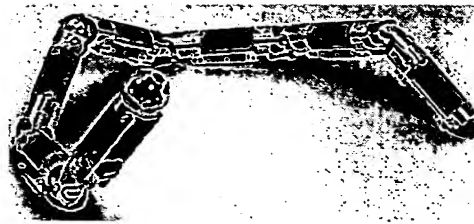


Figure 19b

PRIOR ART

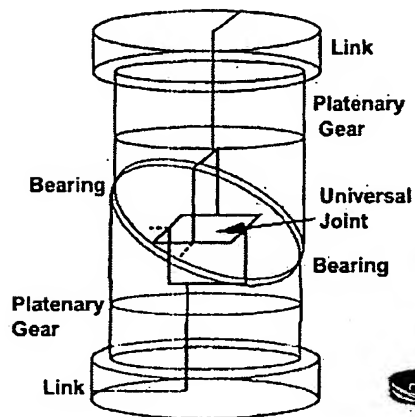


Figure 20a

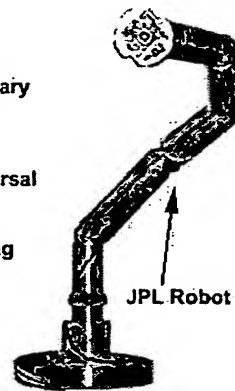


Figure 20b

PRIOR ART

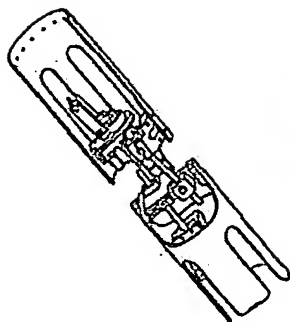


Figure 21a



Figure 21b

PRIOR ART

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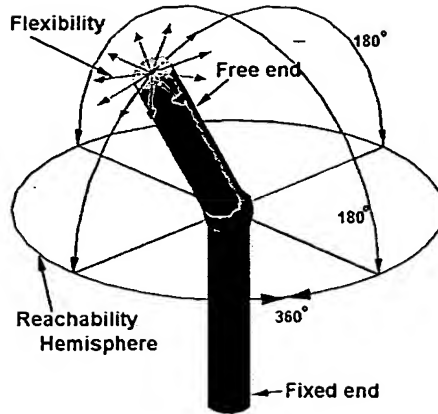


Figure 22

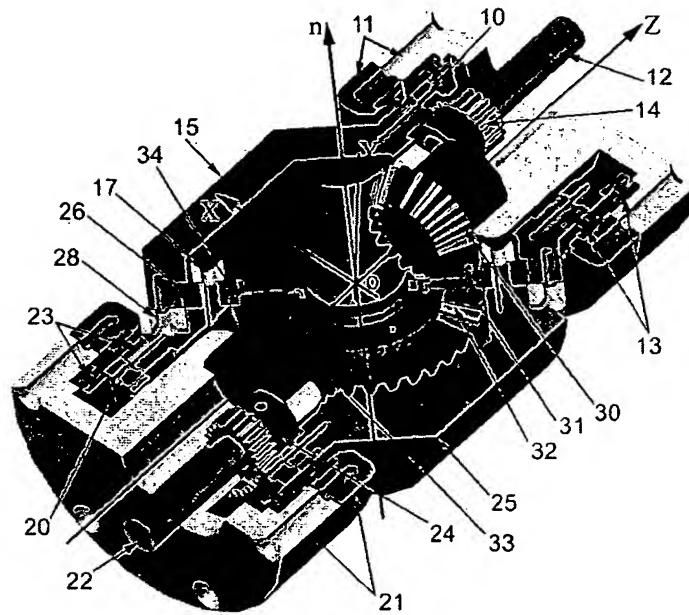


Figure 23

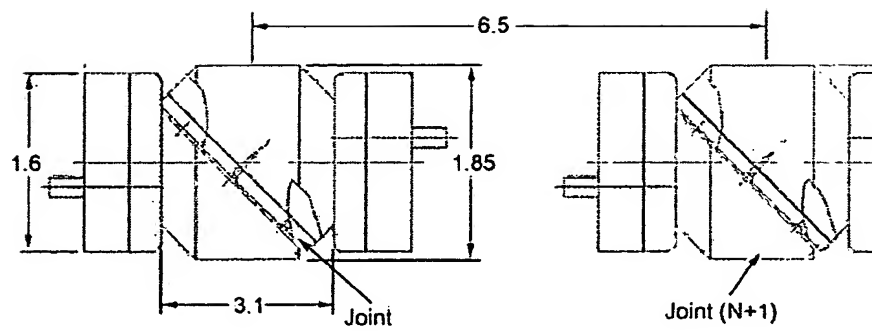


Figure 24

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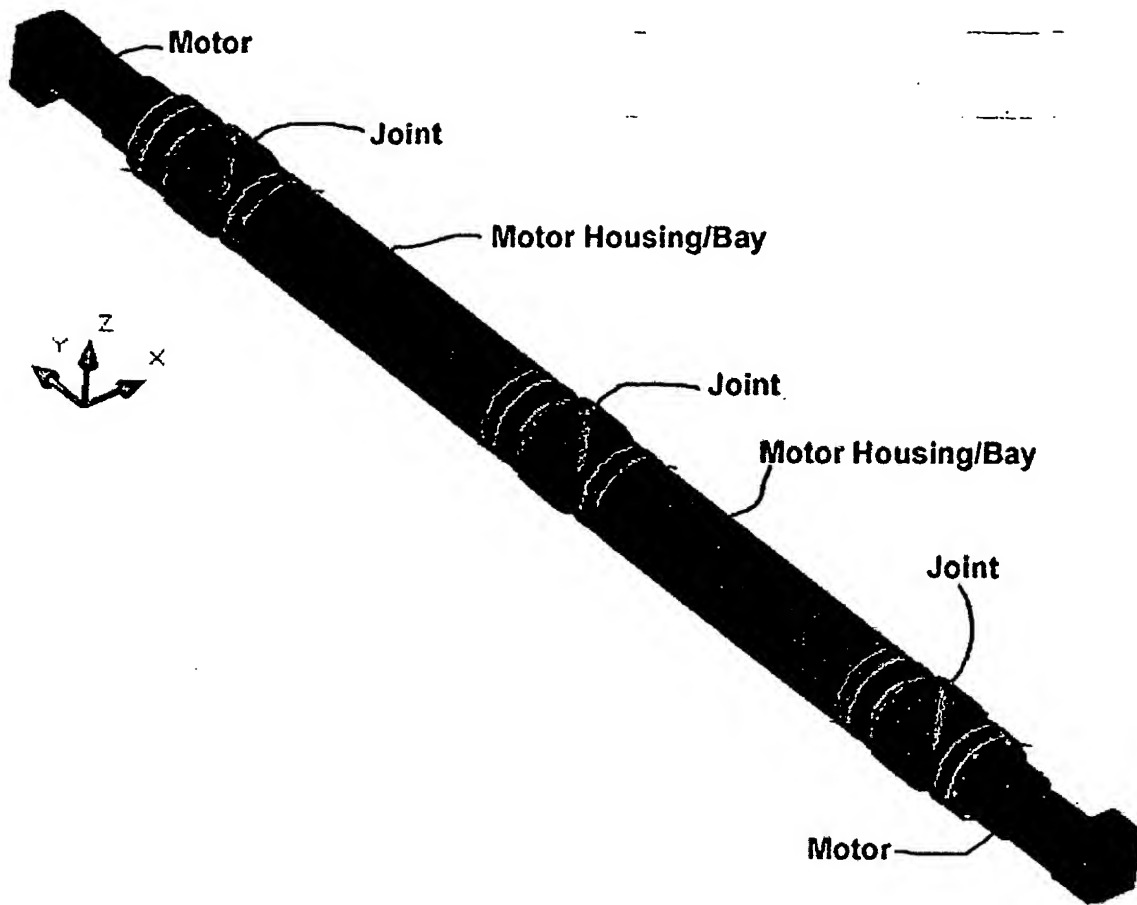


Figure 25.

Figure 25 shows part of a snake robot wherein motor housings / bays are connected together with joints of the present invention.

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